

**Amendments to the Claims:**

This listing of claims will replace all prior versions, and listings, of claims in the application:

**Listing of Claims:**

1. (currently amended) A back-drivable robot head comprising:
  - (a) a manually-graspable driving member;
  - (b) ~~a force sensor for sensing forces applied to the driving member by a user;~~
  - [[c)] an arm for carrying a tool the position of which is to be controlled; and
  - ~~(c)[(d)] a first rotation control mechanism for rotating the arm about a first axis in response to the sensed forces,~~the first rotation control mechanism comprising a first rotational motor [[(30')]] coupled to a first lead screw [[(32)]] and a bearing which moves longitudinally of the first lead screw as it rotates, the bearing being pivotally coupled to an offset crank [[(34)]] of or secured to the arm.
2. (original) A robot head as claimed in claim 1 in which the first motor and the first lead screw are mounted for pivotal motion with respect to a frame of the head.
3. (previously presented) A robot head as claimed in claim 1 in which the first motor is directly secured to the first lead screw, without any intervening gears.
4. (previously presented) A robot head as claimed in claim 1 in which the first lead screw has a high lead angle.
5. (previously presented) A robot head as claimed in claim 1 further including a first output position encoder for measuring the angular position of the arm about the first axis.
6. (previously presented) A robot head as claimed in claim 1 further including a first input position encoder for measuring rotation of the first motor.
7. (currently amended) A robot head as claimed in claim 5 in which the measurement from the first output position encoder is compared with an expected arm position based on the measurement from [[the]] a first input position encoder, and an alarm is raised if the expected position is inconsistent with the actual position.

8. (currently amended) A robot head as claimed in claim 1 further including a second rotation control mechanism for rotating the arm about a second axis, the said mechanism comprising a second rotational motor  $[(30')]$  coupled to a second lead screw  $[(32)]$  and a bearing which moves longitudinally of the second lead screw as it rotates, the bearing being pivotably coupled to an offset crank  $[(34)]$  of or secured to the arm.
9. (original) A robot head as claimed in claim 8 in which the second motor and the second lead screw are mounted for pivotal motion with respect to a frame of the head.
10. (previously presented) A robot head as claimed in claim 8 in which the second motor is directly secured to the second lead screw, without any intervening gears.
11. (previously presented) A robot head as claimed in claim 8 in which the second lead screw has a high lead angle.
12. (previously presented) A robot head as claimed in claim 8 further including a second output position encoder for measuring the angular position of the arm about the second axis.
13. (previously presented) A robot head as claimed in claim 8 further including a second input position encoder for measuring rotation of the second motor.
14. (currently amended) A robot head as claimed in claim 12 in which the measurement from the second output position encoder is compared with an expected arm position based on the measurement from  $[\text{the}]$  a second input position encoder, and an alarm is raised if the expected position is inconsistent with the actual position.
15. (previously presented) A robot head as claimed in claim 8 in which the first axis is perpendicular to the second.
16. (previously presented) A robot head as claimed in claim 8 in which the arm is extendible along a third axis.

17. (previously presented) A robot head as claimed in claim 15 in which the first, second and third axes intersect at a point.
18. (original) A robot head as claimed in claim 16 in which the arm is extendible on a third lead screw which is rotated by a third rotational motor.
19. (previously presented) A robot head as claimed in claim 16 further including a third output position encoder for measuring the extension position of the arm.
20. (original) A robot head as claimed in claim 18 including a third input position encoder for measuring rotation of the third motor.
21. (currently amended) A robot head as claimed in claim 19 in which the measurement from the third output position encoder is compared with an expected arm extension position based on the measurement from ~~[[the]]~~ a third input encoder, and an alarm is raised if the expected position is inconsistent with the actual position.
22. (currently amended) A back-drivable robot head comprising:
- (a) a manually-graspable driving member;
  - (b) ~~a force sensor for sensing forces applied to the driving member by a user;~~
  - ~~[[c]]~~ an arm for carrying a tool the position of which is to be controlled; and
  - ~~(c)~~~~[[d]]~~ a first rotation control mechanism for rotating the arm about a first axis ~~in response to the sensed forces,~~
- the first rotation control mechanism comprising a first rotational motor ~~[[30']]~~, an output of which is converted first to longitudinal motion and then back to rotational motion of the arm.
23. (currently amended) A back-drivable robot head comprising:
- (a) a manually-graspable driving member;
  - (b) ~~a force sensor for sensing forces applied to the driving member by a user;~~
  - ~~[[c]]~~ an arm for carrying a tool the position of which is to be controlled; and

(c)[(d)] a first rotation control mechanism for rotating the arm about a first axis ~~in~~  
~~response to the sensed forces,~~

the first rotation control mechanism comprising a first rotational motor [(30')], an output of which is converted first to longitudinal motion and then back to rotational motion of the arm, the head further including a first input encoder for measuring rotation of the first motor [(30')], a first output encoder for measuring the angular position of the arm about the first axis, and in which the measurement from the first output position encoder is compared with an expected arm position based on the measurement from the first input position encoder, an alarm being raised if the expected position is inconsistent with the actual position.

24. (new) A robot head as claimed in claim 1 further comprising a force sensor for sensing forces applied to the driving member by a user.

25. (new) A robot head as claimed in claim 24 wherein the first rotational control mechanism is arranged to rotate the arm about the first axis in response to the sensed forces.